L Number	Hits	Search Text	DB	Time stamp
- Trainbei	89	702/\$.ccls. and (position same orientation same data) and	USPAT;	2004/10/28 17:28
		(sens\$3 with position) and target	US-PGPUB	200 ./ 10/20 17.20
-	10	(702/\$.ccls. and (position same orientation same data) and	USPAT;	2004/10/30 14:31
İ		(sens\$3 with position) and target) and (transmit\$6 with	US-PGPUB	200 1/20/00 2 1.02
		control with signal)		
-	2	702/\$.ccls. and (position same orientation same data) and	USPAT;	2004/09/26 12:19
	_	(identif\$4 with target with device)	US-PGPUB	200 1,00,20 22:25
i -	O	(702/\$.ccls. and (position same orientation same data) and	USPAT;	2004/09/26 12:14
		(identif\$4 with target with device)) and (transmit\$6 with	US-PGPUB	,,
		control with signal)		
-	o	(702/\$.ccls. and (position same orientation same data) and	USPAT;	2004/09/26 12:14
		(identif\$4 with target with device)) and (control with	US-PGPUB	
		signal)		
-	10	702/\$.ccls. and (position same orientation same data) and	USPAT;	2004/09/26 12:23
, i		(identif\$4 with target with location)	US-PGPUB	
_	1	10/010104	USPAT;	2004/09/26 12:25
		· ·	US-PGPUB	
} -	1	5963145.pn.	USPAT;	2004/09/26 12:25
		· ·	US-PGPUB	, , ==:==
- !	0	(702/\$.ccls. and (position same orientation same data) and	USPAT;	2004/09/26 13:27
		(sens\$3 with position) and target) and (transmit\$6 with	US-PGPUB	
†		control with signal) and (identif\$4 with target with location)		
-	1	(702/\$.ccls. and (position same orientation same data) and	USPAT;	2004/09/26 13:35
	:	(identif\$4 with target with location) and (control\$3 with	US-PGPUB	}
		signal))		
-	11	702/\$.ccls. and (position same orientation same data) and (USPAT;	2004/09/26 13:37
		(three-dimensional or 3D) with Cartesian)	US-PGPUB	
-	5	(702/\$.ccls. and (position same orientation same data) and	USPAT;	2004/09/26 13:37
		((three-dimensional or 3D) with Cartesian)) and RF	US-PGPUB	
-	66	((electronic near2 appliance) (air adj condition) television	USPAT;	2004/10/28 17:43
		(streo near2 sound near2 system) photocop\$4 printer	US-PGPUB;	
		(screen near2 display)) and (RF (radio near2 frequency)	EPO; JPO;	
		(communication near2 cable)) and (workstation (mobile	DERWENT;	
}		near2 terminal) (personal near2 digital near2 assistant) PDA	IBM_TDB	
· .		handheld) and controller and (point\$3 with alignment) and		
·		(sensor with position) and orientation	LICDAT	2004/40/20 47:44
-	3	(((electronic near2 appliance) (air adj condition) television	USPAT;	2004/10/28 17:44
		(streo near2 sound near2 system) photocop\$4 printer	US-PGPUB;	
		(screen near2 display)) and (RF (radio near2 frequency)	EPO; JPO;	
		(communication near2 cable)) and (workstation (mobile	DERWENT; IBM_TDB	
		near2 terminal) (personal near2 digital near2 assistant) PDA handheld) and controller and (point\$3 with alignment) and	מטו_ויוטג	
		(sensor with position) and orientation) and (stor\$3 with		
		location with information)		
_	3	(((electronic near2 appliance) (air adj condition\$3) television	USPAT;	2004/10/28 17:44
1		((cleect offic real 2 appliance) (all adj conditions) television (streo near2 sound near2 system) photocop\$4 printer	US-PGPUB;	200 1/ 10/20 17.11
		(screen near2 display)) and (RF (radio near2 frequency)	EPO; JPO;	
		(communication near2 cable)) and (workstation (mobile	DERWENT;	
		near2 terminal) (personal near2 digital near2 assistant) PDA	IBM_TDB	
		handheld) and controller and (point\$3 with alignment) and		
		(sensor with position) and orientation) and (stor\$3 with		
		location with information)		
-	66	((electronic near2 appliance) (air adj condition\$3) television	USPAT;	2004/10/28 17:47
		(streo near2 sound near2 system) photocop\$4 printer	US-PGPUB;	, ==, == ==,
		(screen near2 display)) and (RF (radio near2 frequency)	EPO; JPO;	
		(communication near2 cable)) and (workstation (mobile	DERWENT;	
		near2 terminal) (personal near2 digital near2 assistant) PDA	IBM_TDB	
		handheld) and controller and (point\$3 with alignment) and		
		(sensor with position) and orientation		

-	43	(((electronic near2 appliance) (air adj condition\$3) television (streo near2 sound near2 system) photocop\$4 printer	USPAT; US-PGPUB;	2004/10/28 17:47
		(screen near2 display)) and (RF (radio near2 frequency)	EPO; JPO;	
			DERWENT;	
	ļ	(communication near2 cable)) and (workstation (mobile		
		near2 terminal) (personal near2 digital near2 assistant) PDA	IBM_TDB	
		handheld) and controller and (point\$3 with alignment) and		
	ł	(sensor with position) and orientation) and (network\$3 with		
	40	device)	LICDAT.	2004/10/20 17:40
_	40	((((electronic near2 appliance) (air adj condition\$3)	USPAT;	2004/10/28 17:48
	!	television (streo near2 sound near2 system) photocop\$4	US-PGPUB;	
		printer (screen near2 display)) and (RF (radio near2	EPO; JPO;	
		frequency) (communication near2 cable)) and (workstation	DERWENT;	
		(mobile near2 terminal) (personal near2 digital near2	IBM_TDB	
		assistant) PDA handheld) and controller and (point\$3 with		
		alignment) and (sensor with position) and orientation) and		
		(network\$3 with device)) and (control\$3 with signal) and		
		(user with input\$3)		
-	1	(((((electronic near2 appliance) (air adj condition\$3)	USPAT;	2004/10/28 17:49
	1	television (streo near2 sound near2 system) photocop\$4	US-PGPUB;	
	!	printer (screen near2 display)) and (RF (radio near2	EPO; JPO;	
	1	frequency) (communication near2 cable)) and (workstation	DERWENT;	
	1	(mobile near2 terminal) (personal near2 digital near2	IBM_TDB	
	1	assistant) PDA handheld) and controller and (point\$3 with		
		alignment) and (sensor with position) and orientation) and		
	1	(network\$3 with device)) and (control\$3 with signal) and		
		(user with input\$3)) and (sens\$3 with orientation)		
-	40	(((((electronic near2 appliance) (air adj condition\$3)	USPAT;	2004/10/28 17:49
		television (streo near2 sound near2 system) photocop\$4	US-PGPUB;	
	1	printer (screen near2 display)) and (RF (radio near2	EPO; JPO;	
]	frequency) (communication near2 cable)) and (workstation	DERWENT;	
		(mobile near2 terminal) (personal near2 digital near2	IBM_TDB	
		assistant) PDA handheld) and controller and (point\$3 with		
	!	alignment) and (sensor with position) and orientation) and		
	1	(network\$3 with device)) and (control\$3 with signal) and		
		(user with input\$3)) and target	LICDAT	2004/40/20 47:57
- , -	1	((((((electronic near2 appliance) (air adj condition\$3)	USPAT;	2004/10/28 17:57
		television (streo near2 sound near2 system) photocop\$4	US-PGPUB;	
		printer (screen near2 display)) and (RF (radio near2	EPO; JPO;	
		frequency) (communication near2 cable)) and (workstation	DERWENT;	
		(mobile near2 terminal) (personal near2 digital near2	IBM_TDB	
		assistant) PDA handheld) and controller and (point\$3 with		
		alignment) and (sensor with position) and orientation) and		
		(network\$3 with device)) and (control\$3 with signal) and		
	. '	(user with input\$3)) and target) and (select\$3 with target)	LICDATE	2004/10/20 10:00
-	1	target and (sens\$3 with position) and (sens\$3 with	USPAT;	2004/10/28 18:00
		orientation) and (position with data) and ((control\$3 with	US-PGPUB;	
		signal) same (position with data) same orientation same	EPO; JPO;	
		(user with input\$3)) and communication and controller	DERWENT;	
_		(const2 with position) and (const2 with orientation) and	IBM_TDB	2004/10/29 19:01
-	1	(sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/28 18:01
		(position with data) and ((control\$3 with signal) same	US-PGPUB;	
	1	(position with data) same orientation same (user with	EPO; JPO;	
		input\$3)) and communication and controller	DERWENT;	
		(conct2 with nacition) and (const2 with suitables)	IBM_TDB	2004/10/20 12:01
-	6	(sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/30 13:01
		(position with data) and ((control\$3 with signal) same	US-PGPUB;	
		(position with data) same orientation same (user with input\$3)) and communication and (controller CPU computer	EPO; JPO; DERWENT;	
		microcomputer)	IBM_TDB	
L	L	microcomputer)	םטו_ויוטג	l

-	1	((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 15:13
		(position with data) and ((control\$3 with signal) same	US-PGPUB;	
		(position with data) same orientation same (user with	EPO; JPO;	
		input\$3)) and communication and (controller CPU computer	DERWENT;	
		microcomputer)) and target	IBM_TDB	2004/40/20 40 05
-	1	((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/28 18:02
		(position with data) and ((control\$3 with signal) same	US-PGPUB;	
		(position with data) same orientation same (user with	EPO; JPO;	
		input\$3)) and communication and (controller CPU computer	DERWENT;	
		microcomputer)) and network\$3	IBM_TDB	
-	2	5963145.pn.	USPAT;	2004/10/29 15:08
			US-PGPUB;	
			EPO; JPO;	
			DERWENT;	
			IBM_TDB	
-	1	((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 15:14
		(position with data) and ((control\$3 with signal) same	US-PGPUB;	
		(position with data) same orientation same (user with	EPO; JPO;	
		input\$3)) and (IR with communication) and (controller CPU	DERWENT;	
		computer microcomputer))	IBM_TDB	
-	9	((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 17:44
		(position with data) and (control\$3 with signal) and (user	US-PGPUB;	
	Ì	with input\$3) and (IR with communication) and (controller	EPO; JPO;	
	}	CPU computer microcomputer))	DERWENT;	
		' "	IBM_TDB	
_	224	((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 16:16
		(position with data) and (control\$3 with signal) and	US-PGPUB;	, ,
		(controller CPU computer microcomputer)) and gyroscope	EPO; JPO;	
		(denial one of company) and gyrosospe	DERWENT;	
			IBM_TDB	
_	97	(((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 16:17
		(position with data) and (control\$3 with signal) and	US-PGPUB;	
		(controller CPU computer microcomputer)) and gyroscope)	EPO; JPO;	
		and ((sens\$3 with orientation) same gyroscope)	DERWENT;	
		and ((conoquinarion) came 5/1 coope)	IBM_TDB	
- .	35	((((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 16:17
		(position with data) and (control\$3 with signal) and	US-PGPUB;	,,
		(controller CPU computer microcomputer)) and gyroscope)	EPO; JPO;	
		and ((sens\$3 with orientation) same gyroscope)) and	DERWENT;	
		point\$3 and target	IBM TDB	
_	3	(((((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 16:40
		(position with data) and (control\$3 with signal) and	US-PGPUB;	, ==,==
		(controller CPU computer microcomputer)) and gyroscope)	EPO; JPO;	
		and ((sens\$3 with orientation) same gyroscope)) and	DERWENT;	
		point\$3 and target) and (point with shape)	IBM_TDB	
-	9	((((((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 16:40
	1	(position with data) and (control\$3 with signal) and	US-PGPUB;	
	1	(controller CPU computer microcomputer)) and gyroscope)	EPO; JPO;	
	1	and ((sens\$3 with orientation) same gyroscope)) and	DERWENT;	
,	1	point\$3 and target) and (select\$3 with target)	IBM_TDB	
_	34	(sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 17:45
		(position with data) and (control\$3 with signal) and (user	US-PGPUB;	
		with input\$3) and (infrared with communication) and	EPO; JPO;	
	1	gyroscope	DERWENT;	
	1	37. 0000pc	IBM_TDB	
_	1	((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 17:46
	1	(sensas with position) and (sensas with orientation) and (position with data) and (control\$3 with signal) and (user	US-PGPUB;	2007/10/23 17.40
		with input\$3) and (infrared with communication) and	EPO; JPO;	
	1			
		gyroscope) and (point\$3 with shape)	DERWENT;	
	1		IBM_TDB	

((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (point\$3 with orientation) and (position with data) and (p	29 17:47 29 17:48 29 17:50
with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target 1 (((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (point\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (point\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (point\$3 with signal) and (user with input\$3 w	29 17:48 29 17:50
gyroscope) and point\$3 and target 1 (((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and (point\$3 with print\$3) 2 7 (((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless 2 4 ((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency)) 3 0 ((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) 4 0 ((((sens\$3 with position)) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) 5 0 ((((sens\$3 with position)) and (sens\$3 with orientation) and (sens\$3 with position) and (sens\$3 with orientation) and (sens\$3 with position) and (sens\$3 with orientation) and (sens\$4 with communication) and (sens\$5 with position) and (sens\$5 with orientation) and (sens\$7 with signal) and (rebot with arm) 6 0 ((((sens\$3 with position)) and (robot with arm) (sens\$3 with position) with data) and (point\$3 with shape) and (robot with arm) (sens\$3 with position) and (point\$3 with shape) and (robot with arm) (sens\$3 with orientation) and (point\$3 with shape) and (robot with arm) (sens\$3 with orientation) and (point\$3 with shape) and (robot with arm) (sens\$3 with orientation) and (point\$3 with shape) and (robot with ar	29 17:48 29 17:50
Continue of the continue of	29 17:48 29 17:50
1 (((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with orientation) and (position with data) and (point\$3 with orientation) and (position with data) and (point\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot with arm) (position with data) and (point\$3 with shape) and (robot with arm) and (position with data) and (point\$3 with shape) and (robot with arm) and (position with data) and (point\$3 with shape) and (robot with arm) and (position with data) and (point\$3 with shape) and (pobatical points) and (position with data) and (point\$3 with orientation) and (position with data) and (point\$3 with shape) and (pobatical points) and (position with data) and (point\$3 with orientation) an	29 17:48 29 17:50
(position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and (point\$3 with perint\$3) 27 (((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless 24 ((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency)) (((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (point\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and gyroscope	29 17:48 29 17:50
with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and (point\$3 with print\$3) 27 (((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) 10 (sens\$3 with position) and (sens\$3 with orientation) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) 2004/10/2	29 17:50
gyroscope) and point\$3 and target) and (point\$3 with print\$3) ((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with orientation) and (position with data) and (control\$3 with signal) and (user (position with data) and (control\$3 with signal) and (user (position with data) and (control\$3 with signal) and (user (position with data) and (control\$3 with signal) and (user (position with data) and (robot with arm) 0 (((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (robot with arm) (position with data) and (point\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and (position with data) and (point\$3 with shape) and (robot with arm) and (position with data) and (point\$3 with shape) and (position with arm) and (position with data) and (point\$3 with shape) and (position with arm) and (position with arm) and (position with arm) and (position with arm) and (positio	29 17:50
print\$3) (((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user (radio near2 frequency)) (((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (robot with arm) (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (robot with arm) (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and gyroscope (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and gyroscope	29 17:50
- 27 (((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (position with data) and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) 10 (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot (position with data) and (point\$3 with shape) and (robot (position with data) and (point\$3 with shape) and (robot (position with data) and (point\$3 with shape) and (robot (position with data) and (point\$3 with shape) and (robot (position with data) and (point\$3 with shape) and (robot (position with data) and (point\$3 with shape) and (robot (position with data) and (point\$3 with shape) and (robot (position with data) and (point\$3 with shape) and (robot (position with data) and (point\$3 with shape) and (robot (position with data) and (point\$3 with shape) and (position (position with data) and (position with data)	29 17:50
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with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless - 24 ((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency)) - 0 (((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) - 0 (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot US-PGPUB; with arm) and (infrared with communication) and gyroscope with arm) and (infrared with communication) and (position with data) and (point\$3 with shape) and (robot US-PGPUB; EPO; JPO; DERWENT;	
gyroscope) and point\$3 and target) and wireless - 24 ((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency)) - 0 (((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and (gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) - 0 (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot with arm) (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and gyroscope DERWENT; 2004/10/2 2004	
- 24 ((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency)) - 0 (((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) - 0 (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and gyroscope USPAT; US-PGPUB; EPO; JPO; DERWENT; US-PGPUB; EPO; JPO; DERWENT; US-PGPUB; EPO; JPO; DERWENT; EPO; JPO;	
- ((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency)) - ((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) - (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and gyroscope with arm) and (infrared with communication) and gyroscope USPAT; 2004/10/2 2	
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gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency)) ((((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot US-PGPUB; with arm) and (infrared with communication) and gyroscope (position with data) and (point\$3 with shape) and (robot US-PGPUB; with arm) and (infrared with communication) and gyroscope DERWENT;	29 17:50
(radio near2 frequency)) (((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot US-PGPUB; with arm) and (infrared with communication) and gyroscope (position with data) and (point\$3 with shape) and (robot US-PGPUB; with arm) and (infrared with communication) and gyroscope (position with data) and (point\$3 with shape) and (robot US-PGPUB; EPO; JPO; DERWENT;	29 17:50
- 0 (((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) - 0 (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and gyroscope USPAT; US-PGPUB; DERWENT; US-PGPUB; US-PGPU	29 17:50
(position with data) and (control\$3 with signal) and (user with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) 1 (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and gyroscope 1 (S-PGPUB; EPO; JPO; DERWENT;	
with input\$3) and (infrared with communication) and gyroscope) and point\$3 and target) and wireless) and (RF or (radio near2 frequency))) and (robot with arm) 0 (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and gyroscope with input\$3) and (infrared with communication) and (RF or DERWENT; USPAT; US-PGPUB; EPO; JPO; DERWENT;	
(radio near2 frequency))) and (robot with arm) (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and gyroscope With arm) and (infrared with communication) and gyroscope DERWENT;	
- 0 (sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and gyroscope (EPO; JPO; DERWENT;	
(position with data) and (point\$3 with shape) and (robot with arm) and (infrared with communication) and gyroscope EPO; JPO; DERWENT;	
with arm) and (infrared with communication) and gyroscope EPO; JPO; DERWENT;	29 17:52
DERWENT;	
IBM TDB	
	20.40.40
- 7 (sens\$3 with position) and (sens\$3 with orientation) and USPAT; 2004/10/2	29 18:10
(position with data) and point\$3and (robot with arm) and US-PGPUB;	
(infrared with communication) and gyroscope EPO; JPO;	
DERWENT; IBM_TDB	
0 (sens\$3 with position) and (sens\$3 with orientation) and USPAT; 2004/10/2	20 10 11
(position with data) and (robot with arm) and (infrared with US-PGPUB;	15 10.11
communication) and (gyroscope with orientation) EPO; JPO;	
DERWENT;	
IBM_TDB	
- 0 (sens\$3 with position) and (sens\$3 with orientation) and USPAT; 2004/10/2	29 18-12
(position with data) and (robot with arm) and (infrared with US-PGPUB;	10.12
communication) and (gyroscope same orientation) EPO; JPO;	
DERWENT;	
IBM_TDB	
- 0 (sens\$3 with position) and (sens\$3 with orientation) and USPAT; 2004/10/2	29 18:12
(position with data) and (robot\$6 with arm) and (infrared US-PGPUB;	·
with communication) and (gyroscope same orientation) EPO; JPO;	
DERWENT;	
IBM_TDB	
- 0 (sens\$3 with position) and (sens\$3 with orientation) and USPAT; 2004/10/2	29 18:12
(position with data) and robot\$6 and (infrared with US-PGPUB;	
communication) and (gyroscope same orientation) EPO; JPO;	
DERWENT;	
IBM_TDB	
- 24 (sens\$3 with position) and (sens\$3 with orientation) and USPAT; 2004/10/3	30 11:20
(position with data) and (infrared with communication) and US-PGPUB;	
(gyroscope same orientation) EPO; JPO;	
DERWENT; IBM_TDB	

-	95	(sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (infrared with communication) and	USPAT; US-PGPUB;	2004/10/29 18:54
		(point\$3 same display\$3)	EPO; JPO; DERWENT;	
:			IBM_TDB	
-	16	(sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 19:09
		(position with data) and (infrared with communication) and	US-PGPUB;	
		(point\$3 same display\$3) and (point\$3 same print\$3)	EPO; JPO; DERWENT;	
			IBM_TDB	
-	45	(sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 18:56
		(position with data) and (point\$3 with display\$3) and	US-PGPUB;	
		(point\$3 with print\$3)	EPO; JPO;	
			DERWENT; IBM_TDB	
_	2	((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 19:16
	_	(position with data) and (point\$3 with display\$3) and	US-PGPUB;	200 1/10/25 15:10
		(point\$3 with print\$3)) and (infrared with communication)	EPO; JPO;	
			DERWENT;	
	26	40 10 10 10 10 10 10 10 10 10 10 10 10 10	IBM_TDB	2004/40/20 40 07
-	26	((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 19:07
ļ		(position with data) and (point\$3 with display\$3) and (point\$3 with print\$3)) and infrared and communication	US-PGPUB; EPO; JPO;	
		(points with prints)) and initiated that communication	DERWENT;	
			IBM_TDB	
-	18	("5963145" "5650831" "6078575" "6028764" "5880867"	USPAT;	2004/10/30 14:31
		"5767807" "4959721" "5528264" "5506717").pn.	US-PGPUB;	
			EPO; JPO; DERWENT;	
		,	IBM_TDB	
-	0	(("5963145" "5650831" "6078575" "6028764" "5880867"	USPAT;	2004/10/30 14:30
		"5767807" "4959721" "5528264" "5506717").pn.) and	US-PGPUB;	
		(point\$3 same display\$3) and (point\$3 same print\$3)	EPO; JPO;	
			DERWENT; IBM_TDB	- 1
_	13	(("5963145" "5650831" "6078575" "6028764" "5880867"	USPAT;	2004/10/29 19:40
		"5767807" "4959721" "5528264" "5506717").pn.) and	US-PGPUB;	,,
		point\$3	EPO; JPO;	
			DERWENT;	
_	67	(sens\$3 with position) and (sens\$3 with orientation) and	IBM_TDB USPAT;	2004/10/29 19:16
	67	(point\$3 with display\$3) and (point\$3 with print\$3)	US-PGPUB;	2007/10/29 19:10
		(E-marke man architely and (Eemiste man kinnede)	EPO; JPO;	
			DERWENT;	
	_	((IBM_TDB	2004/10/20 10:17
-	3	((sens\$3 with position) and (sens\$3 with orientation) and (point\$3 with display\$3) and (point\$3 with print\$3)) and	USPAT; US-PGPUB;	2004/10/29 19:17
		(points) with displays) and (points) with prints)) and (infrared with communication)	EPO; JPO;	
		Annual Community	DERWENT;	
			IBM_TDB	
-	35	((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/29 19:17
		(point\$3 with display\$3) and (point\$3 with print\$3)) and	US-PGPUB;	
		infrared and communication	EPO; JPO; DERWENT;	
			IBM_TDB	
-	0	(("5963145" "5650831" "6078575" "6028764" "5880867"	USPAT;	2004/10/29 19:41
		"5767807" "4959721" "5528264" "5506717").pn.) and angle	US-PGPUB;	
		and dimensional	EPO; JPO;	
			DERWENT; IBM_TDB	
L_	I	I	1 -01 1 1 0 0	L

-	0	(("5963145" "5650831" "6078575" "6028764" "5880867" "5767807" "4959721" "5528264" "5506717").pn.) and angle	USPAT; US-PGPUB;	2004/10/29 19:41
		and axesl	EPO; JPO; DERWENT;	
			IBM_TDB	
-	1	(("5963145" "5650831" "6078575" "6028764" "5880867" "5767807" "4959721" "5528264" "5506717").pn.) and angle	USPAT; US-PGPUB;	2004/10/29 19:41
		and axes	EPO; JPO;	
			DERWENT;	
	110	(annet2 with modition) and (annet2 with aviantetion) and	IBM_TDB	2004/10/20 12:00
-	119	(sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (infrared with communication) and	USPAT; US-PGPUB;	2004/10/30 12:09
		(control\$3 with signal) and (transmit\$6 with signal)	EPO; JPO;	
			DERWENT;	
_	92	((sens\$3 with position) and (sens\$3 with orientation) and	IBM_TDB USPAT;	2004/10/30 11:28
	,	(position with data) and (infrared with communication) and	US-PGPUB;	200 1, 10, 50 11.20
		(control\$3 with signal) and (transmit\$6 with signal)) and	EPO; JPO;	
		controller	DERWENT; IBM_TDB	
-	32	(((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/30 11:55
		(position with data) and (infrared with communication) and	US-PGPUB;	, - 1, - 1 - 1
		(control\$3 with signal) and (transmit\$6 with signal)) and	EPO; JPO; DERWENT;	
		controller) and (network\$3 with device)	IBM_TDB	
-	33	(((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/30 11:57
		(position with data) and (infrared with communication) and	US-PGPUB;	
		(control\$3 with signal) and (transmit\$6 with signal)) and controller) and gyroscope	EPO; JPO; DERWENT;	
		controller) and gyroscope	IBM_TDB	
-	29	((((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/30 11:57
		(position with data) and (infrared with communication) and (control\$3 with signal) and (transmit\$6 with signal)) and	US-PGPUB; EPO; JPO;	
		controller) and gyroscope) and RF	DERWENT;	
	30	(((const2 with position) and (const2 with evientation) and	IBM_TDB	2004/10/20 11:57
-	39	(((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (infrared with communication) and	USPAT; US-PGPUB;	2004/10/30 11:57
		(control\$3 with signal) and (transmit\$6 with signal)) and	EPO; JPO;	
		controller) and gyro\$6 and point\$3	DERWENT;	
_	32	((((sens\$3 with position) and (sens\$3 with orientation) and	IBM_TDB USPAT;	2004/10/30 11:57
		(position with data) and (infrared with communication) and	US-PGPUB;	, ,
		(control\$3 with signal) and (transmit\$6 with signal)) and controller) and gyro\$6 and point\$3) and RF	EPO; JPO; DERWENT;	
		conditional yard gyrogo and pointings) and N	IBM_TDB	
-	26	(((((sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/30 11:58
		(position with data) and (infrared with communication) and (control\$3 with signal) and (transmit\$6 with signal)) and	US-PGPUB; EPO; JPO;	
		controller) and gyro\$6 and point\$3) and RF) and target	DERWENT;	
			IBM_TDB	2004/40/20 44 50
-	26	((((((sens\$3 with position) and (sens\$3 with orientation) and (position with data) and (infrared with communication)	USPAT; US-PGPUB;	2004/10/30 11:58
		and (control\$3 with signal) and (transmit\$6 with signal))	EPO; JPO;	
		and controller) and gyro\$6 and point\$3) and RF) and target)	DERWENT;	
	161	and wireless (target with control\$3 with signal) and (sens\$3 with	IBM_TDB USPAT;	2004/10/30 12:11
		position) and (sens\$3 with orientation) and (position with	US-PGPUB;	
		data)	EPO; JPO;	
			DERWENT; IBM_TDB	
	1		<u></u>	·

-	31	((target with control\$3 with signal) and (sens\$3 with	USPAT;	2004/10/30 12:12
Ì		position) and (sens\$3 with orientation) and (position with	US-PGPUB;	
		data)) and (transmit\$3 with signal) and infrared	EPO; JPO;	
			DERWENT;	
			IBM_TDB	
-	0	(702/\$.ccls. and (position same orientation same data) and	USPAT;	2004/10/30 12:53
		(sens\$3 with position) and target) and (transmit\$6 adj5	US-PGPUB	
		control adj1 signal)		
-	6	(702/\$.ccls. and (position same orientation same data) and	USPAT;	2004/10/30 12:54
		(sens\$3 with position) and (sens\$3 with orientation)) and	US-PGPUB	
		(transmit\$6 adj5 control adj1 signal)		
-	7	(702/\$.ccls. and (position with data) and (sens\$3 with	USPAT;	2004/10/30 12:55
		position) and (sens\$3 with orientation)) and (transmit\$6	US-PGPUB	
		adj5 control adj1 signal)		
-	14	(702/\$.ccls. and (position with data) and (sens\$3 with	USPAT;	2004/10/30 12:56
	ĺ	position) and (sens\$3 with orientation)) and (transmit\$6	US-PGPUB	
		with (control adj1 signal))		
-	36	(sens\$3 with position) and (sens\$3 with orientation) and	USPAT;	2004/10/30 13:57
		(position with data) and ((control\$3 with signal) same (user	US-PGPUB;	
		with input\$3)) and communication and (transmit\$6 with	EPO; JPO;	
İ		control\$3 with signal) and (controller CPU computer	DERWENT;	
		microcomputer)	IBM_TDB	
-	2	6289263.pn.	USPAT;	2004/10/30 13:57
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